In the Claims:

1. [currently amended] A method of mobile device control comprising:

moving a surrogate under wireless control by a user; ~~and~~

during the moving, detecting unsuitable degradation of wireless communications of the wireless control; and

in response to the detecting and while the surrogate is still receiving the wireless communications, autonomously moving the surrogate to provide suitable wireless communications of the ~~regain~~ wireless control ~~when the wireless control is lost~~.

2. [original] The method as claimed in claim 1 additionally comprising:

autonomously moving the surrogate along a previously determined route.

3. [currently amended] The method as claimed in claim 1 wherein:

autonomously moving the surrogate to regain wireless control occurs after passage of a period of time following the detecting of the degradation.

4. [original] The method as claimed in claim 1 wherein:

autonomously moving the surrogate includes measuring distance and avoiding collisions by the surrogate.

5. [original] The method as claimed in claim 1 wherein:

moving the surrogate under wireless control includes logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof.

12/06/2007 PCHOMP 00000079 082025 10789669
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6. [original] The method as claimed in claim 1 wherein:

autonomously moving the surrogate uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof; and

autonomously moving the surrogate uses waypoints back along a forward movement path for backtracking movement.

7. [currently amended] A method of mobile telepresencing comprising:

moving a surrogate under real-time wireless control by a user; ~~and~~

autonomously moving the surrogate to an area with adequate wireless coverage to regain wireless control when the wireless control is lost for a period of time; and

while the surrogate is autonomously moving, activating a human perceptible indicator which is perceptible to humans in the presence of the surrogate.

8. [original] The method as claimed in claim 7 additionally comprising:

autonomously moving the surrogate along at least one of a previously determined route, a distance, a destination, a direction, or a combination thereof.

9. [original] The method as claimed in claim 7 wherein:

losing wireless control includes degradation of the control to a threshold level;

autonomously moving the surrogate to regain wireless control occurs after a period of time.

10. [original] The method as claimed in claim 7 wherein:

autonomously moving the surrogate includes;

backtracking while measuring distance and avoiding collisions by the surrogate;

stopping the surrogate for an obstacle; and

resuming backtracking after removal of the obstacle.

11. [original] The method as claimed in claim 7 wherein:

moving the surrogate under wireless control includes logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof.

12. [original] The method as claimed in claim 7 wherein:

autonomously moving the surrogate to backtrack uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof;

autonomously moving the surrogate to backtrack uses a slower speed than forward speed; and

autonomously moving the surrogate uses waypoints back along a forward movement path for backtracking movement considering the slower speed of backtracking.

13. [currently amended] A mobile device control system comprising:

a surrogate movable under wireless control by a user; and

a computer/transceiver system on the surrogate for moving the surrogate to regain wireless control independently of the wireless control after passage of a non-zero amount of time following loss of the ~~when the~~ wireless control ~~is lost~~.

14. [original] The system as claimed in claim 13 wherein:

the computer/transceiver system for autonomously moving the surrogate along a previously determined route.

15. [currently amended] The system as claimed in claim 13 wherein:

the computer/transceiver system for autonomously moving the surrogate to regain wireless control occurs after the surrogate remains stationary for the non-zero amount ~~a period~~ of time.

16. [original] The system as claimed in claim 13 wherein:

the computer/transceiver system for autonomously moving the surrogate includes measuring distance and avoiding collisions by the surrogate.

17. [original] The system as claimed in claim 13 wherein:

the computer/transceiver system includes logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof.

18. [original] The system as claimed in claim 13 wherein:

the computer/transceiver system uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof; and

the computer/transceiver system calculates waypoints back along a forward movement path for backtracking movement.

19. [currently amended] A mobile telepresencing system comprising:

a surrogate movable under ~~real-time~~ wireless control by a user; and

a computer/transceiver system for determining when the wireless control is lost and responsive to the determining, autonomously moving the surrogate to an area not currently receiving adequate coverage of the wireless control, but in which the surrogate previously experienced ~~with~~ adequate ~~wireless~~ coverage of the wireless control, to regain adequate coverage of the wireless control ~~when the wireless control is lost for a period of time~~.

20. [original] The system as claimed in claim 19 additionally comprising:

the computer/transceiver system for autonomously moving the surrogate along at least one of a previously determined route, a distance, a destination, a direction, or a combination thereof.

21. [original] The system as claimed in claim 19 wherein:

the computer/transceiver system for determining degradation of the wireless control to a threshold level;

the computer/transceiver system for autonomously moving the surrogate to regain wireless control occurs after a period of time.

22. [original] The system as claimed in claim 19 wherein:

the computer/transceiver system for autonomously moving the surrogate includes;

backtracking means for measuring distance and avoiding collisions by the surrogate during backtracking;

stopping means for stopping the surrogate for an obstacle; and

means for resuming backtracking after removal of the obstacle.

23. [original] The system as claimed in claim 19 wherein:

the computer/transceiver system includes means for logging forward motion using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof.

24. [original] The system as claimed in claim 19 wherein:

the computer/transceiver system uses logged information of forward movement using at least one of dead reckoning, odometry, directional measurement, differential wheel rotation, and a combination thereof for backtracking;

the computer/transceiver system provides a slower speed than forward speed for backtracking by the surrogate; and

the computer/transceiver system uses waypoints back along a forward movement path for backtracking movement considering the slower speed of backtracking.

25. [new] The method as claimed in claim 1 wherein:

the detecting comprises comparing a performance parameter associated with the wireless communications with a threshold.

26. [new] The method as claimed in claim 25 wherein:

the performance parameter comprises a bandwidth and the threshold comprises an acceptable bandwidth.

27. [new] The method as claimed in claim 26 further comprising:

prior to the detecting, wirelessly transmitting a video signal at the acceptable bandwidth from the surrogate to the user.

28. [new] The method as claimed in claim 10 further comprising:

prior to the resuming of the backtracking, sensing removal of the obstacle; and

wherein the resuming is responsive to the sensing.